

Using Surface-Based GPS Receivers to Validate AIRS Column-Integrated Water Vapor Retrievals

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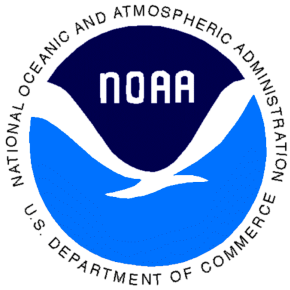
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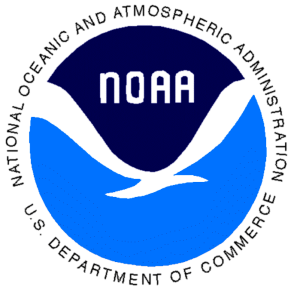
Boulder, CO

<http://gpsmet.fsl.noaa.gov>

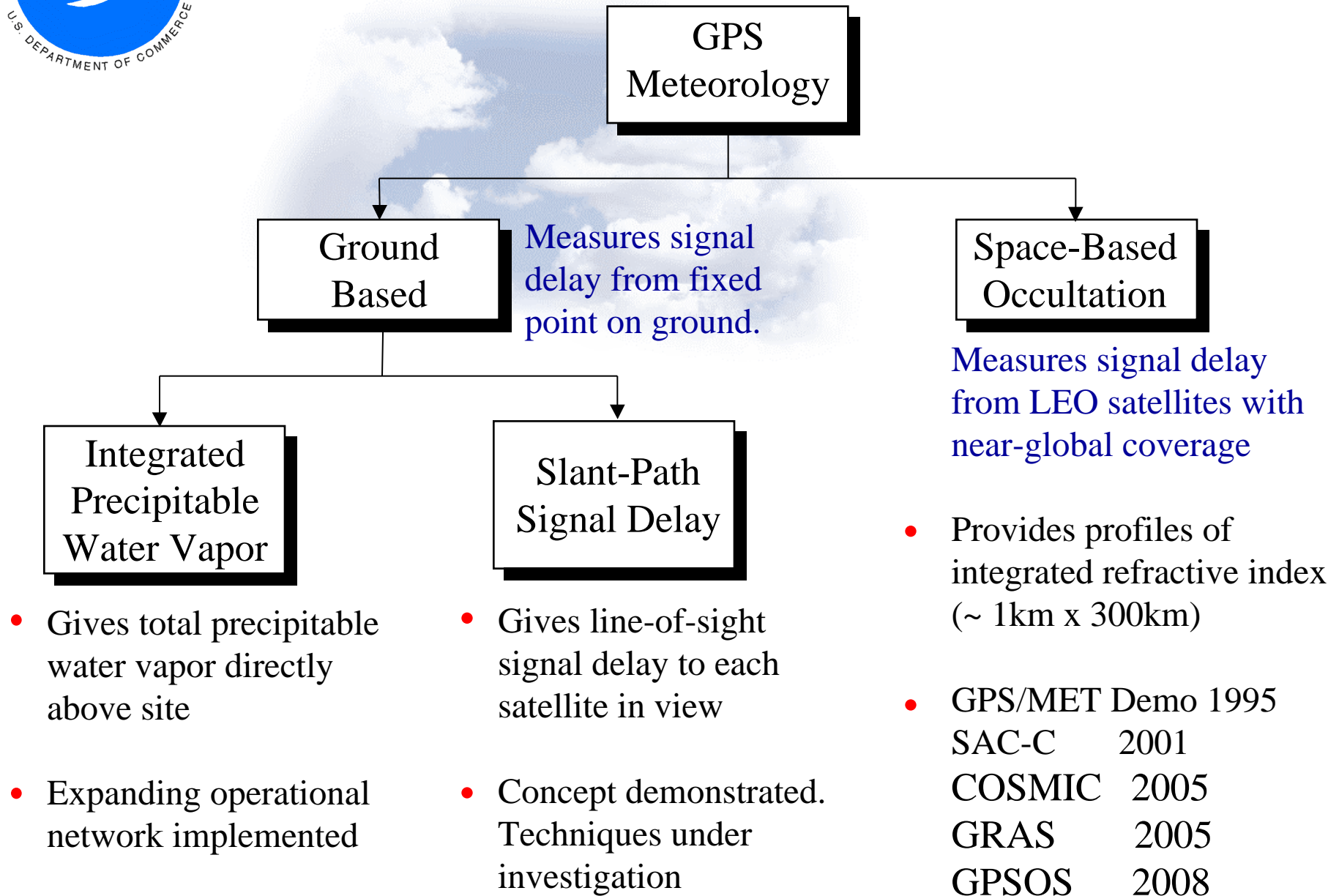


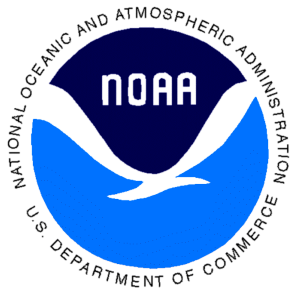
Overview

- GPS-IPW measurement principles
 - GPS-IPW vs. other GPS meteorology
 - Hardware and data collection
 - Signal processing and IPW derivation
- GPS-IPW data products
 - Examples and statistics
- GPS-IPW for AIRS validation
 - Strengths and limitations
 - Schedule and collaboration
 - Special needs

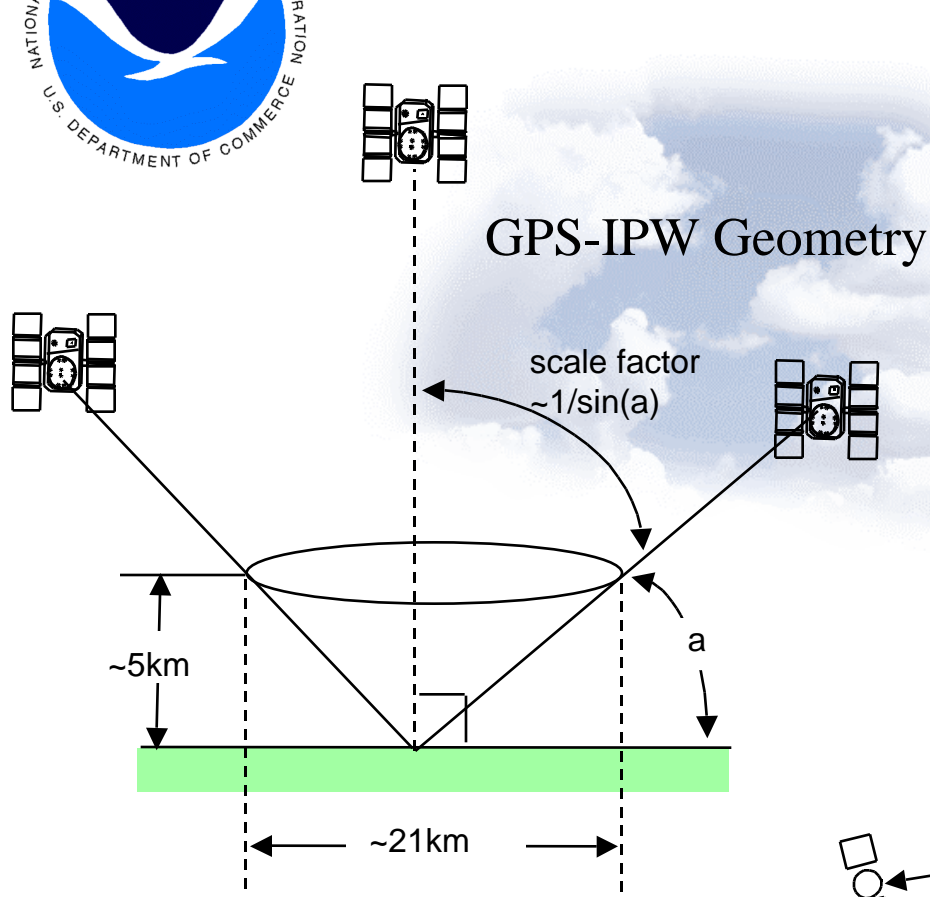


GPS Meteorology



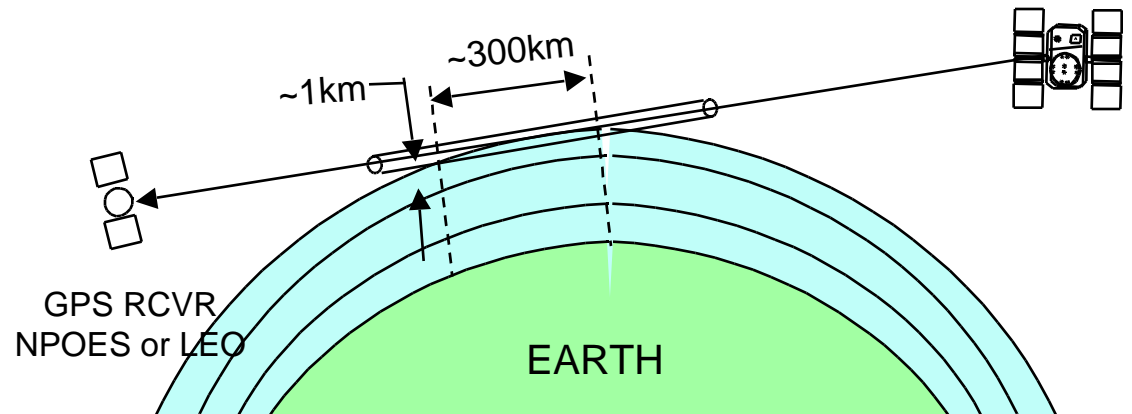
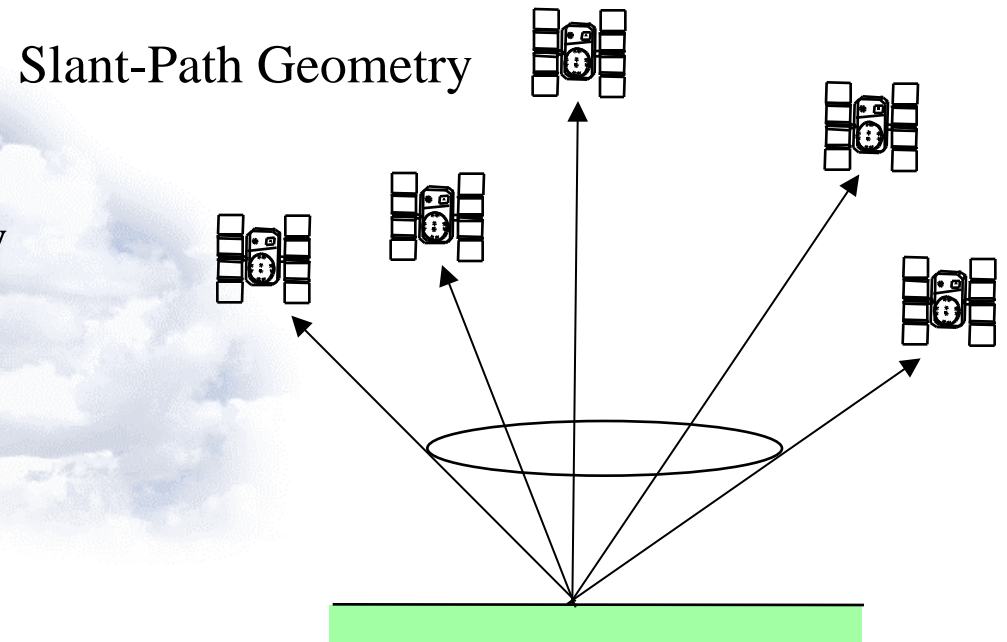


GPS Meteorology Overview



NOTES: Average elevation angle (a) at mid latitudes $\sim 25^\circ$

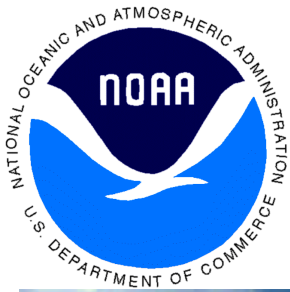
Mapping functions determine how the signal delay changes with elevation angle.



Fundamental Measurement

$$L_s = \int n(s) ds$$

Space Based Geometry



Typical GPS-IPW Network Sites

Demonstration



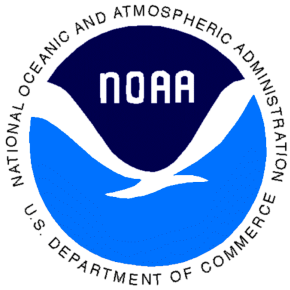
NOAA Wind Profiler Sites
Platteville, CO (PLTC)



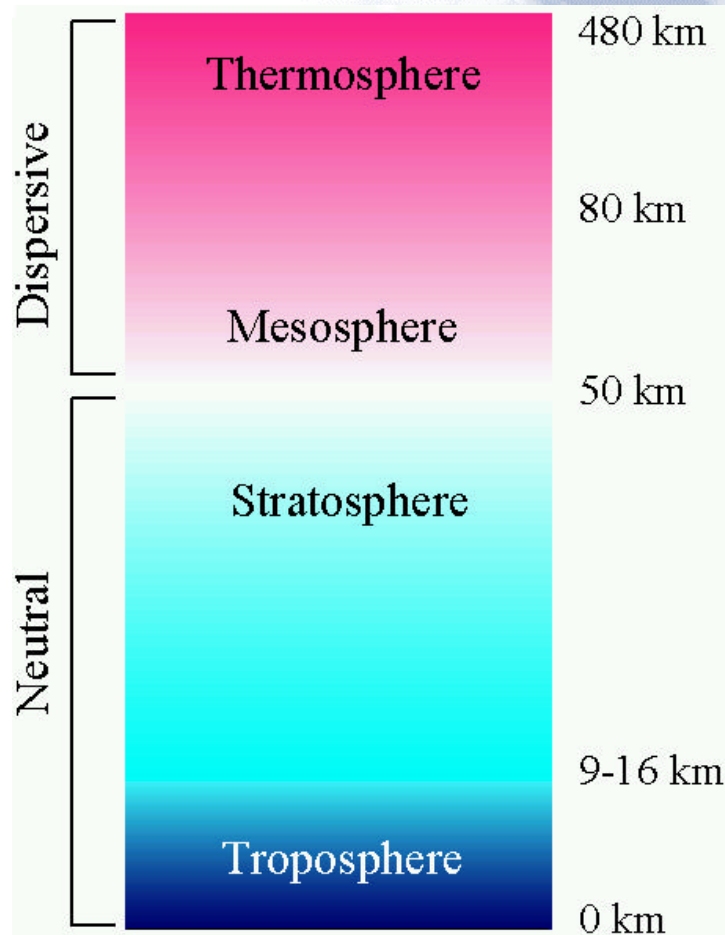
Other NOAA Sites
Blacksburg, VA WFO (BLKV)



USCG and USDOT DGPS Sites
Cape Canaveral, FL (CCV3)



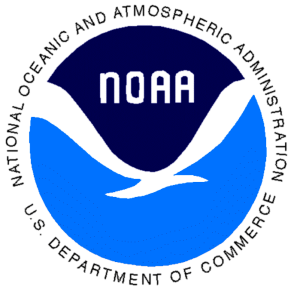
GPS Signal Propagation Through The Atmosphere



- Propagation velocity of EMR in the ionosphere depends on frequency and the refractive index (n) associated with electron density.
- Ionospheric propagation effects can be eliminated using dual frequency receivers since:

$$f_{IF} = 2.546 f_{L1} - 1.984 f_{L2}$$

- Below 30 GHz, EMR propagation velocity in the neutral atmosphere depends on the refractive index associated with temperature, pressure and water vapor.



Tropospheric Signal Delay

- After position is estimated, there are always residual errors caused by slowing and bending of the GPS signal in the neutral atmosphere - the Tropospheric Signal Delay.
- In terms of the refractivity of the neutral atmosphere:

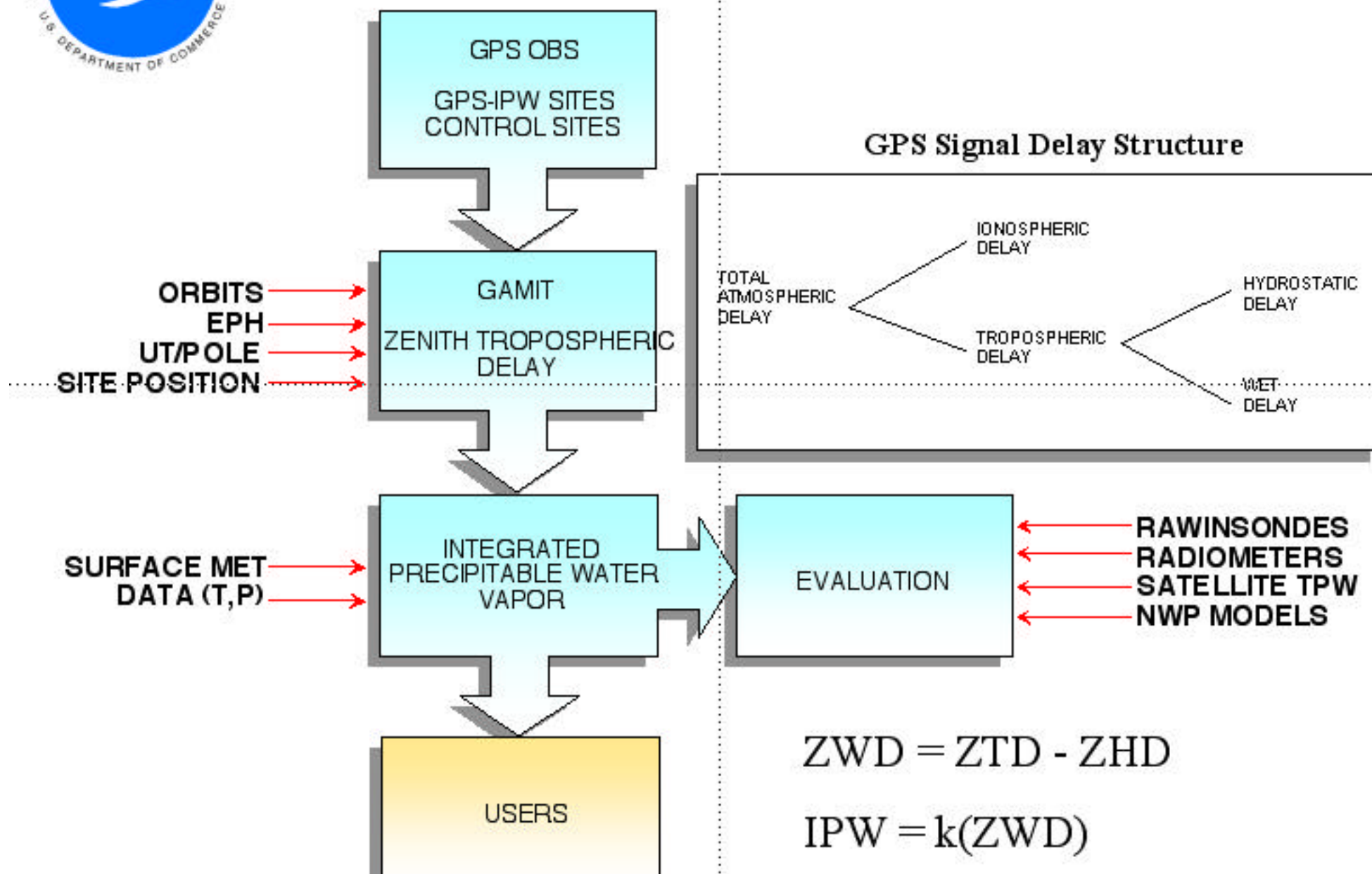
$$N = 10^6(n-1) = k_1 \frac{P_d}{T} + k_2 \frac{P_v}{T} + k_3 \frac{P_v}{T^2}$$

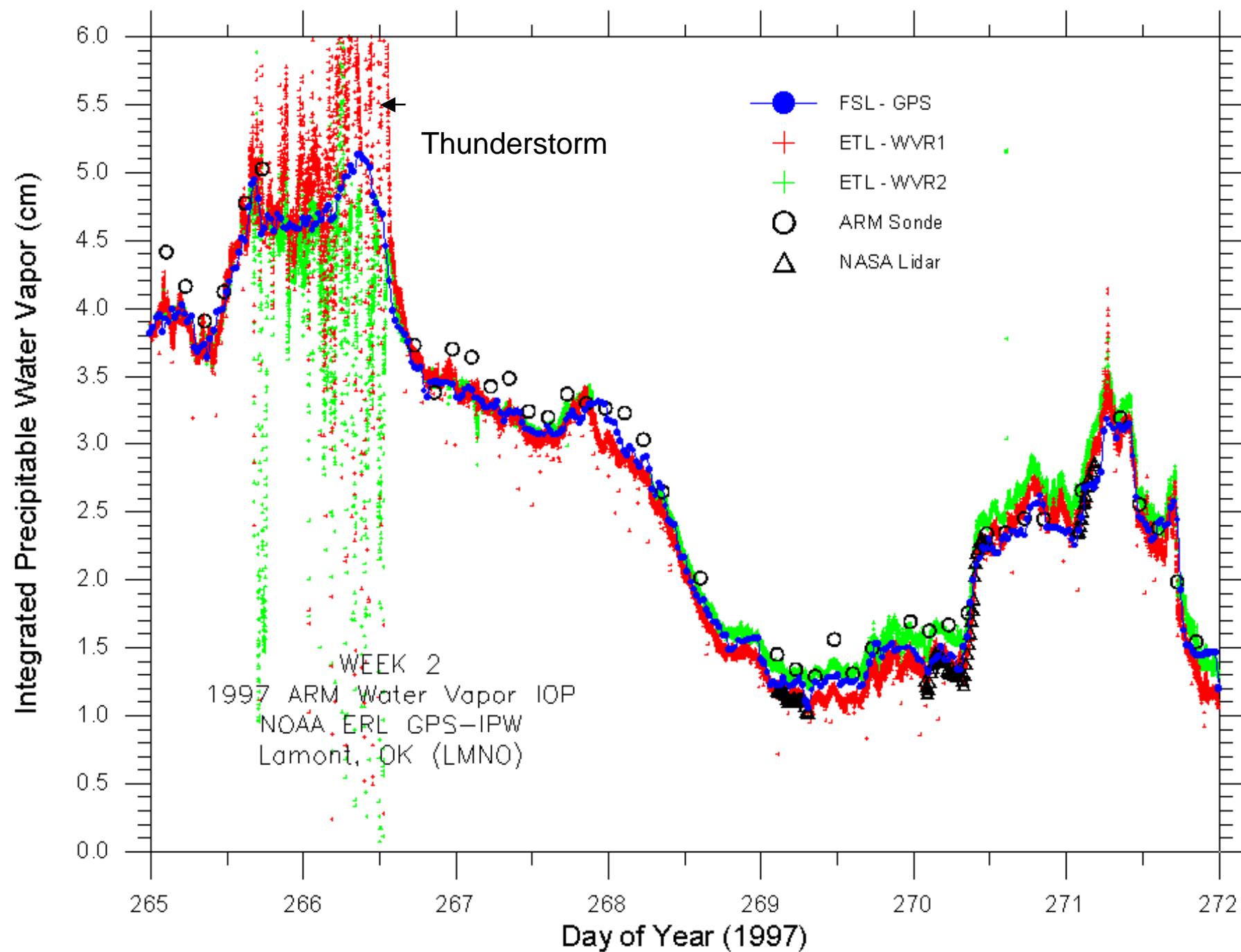
where P_d and P_v are the partial pressures of the dry and wet components of the atmosphere; k_1 , k_2 and k_3 are the gas constants; and T is temperature.

- We apply a mapping function to estimate the signal delay that would be observed if each satellite was directly overhead, and average the results to give ZTD.

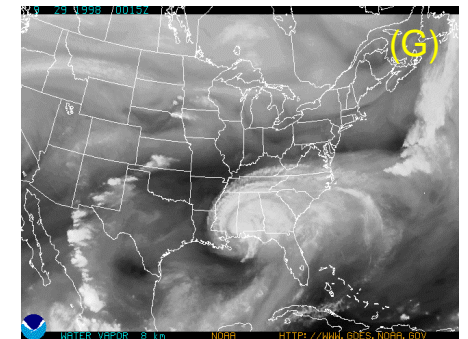
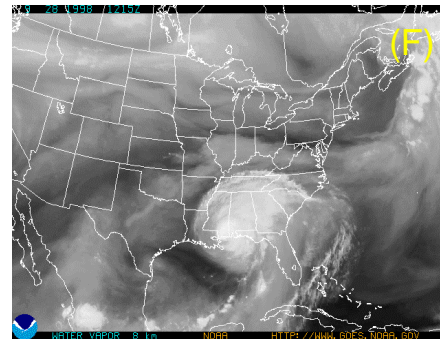
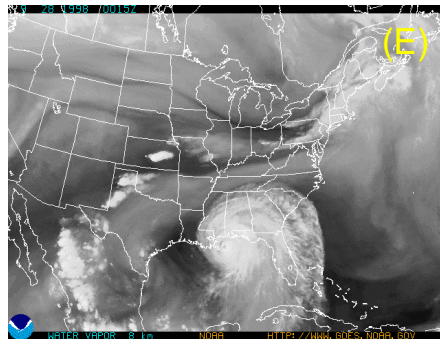
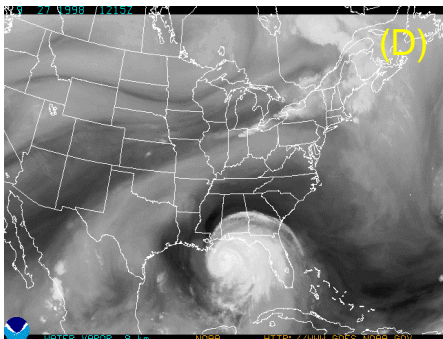
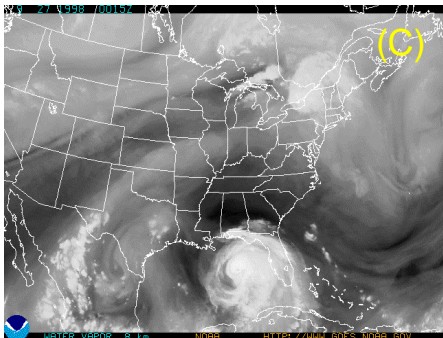
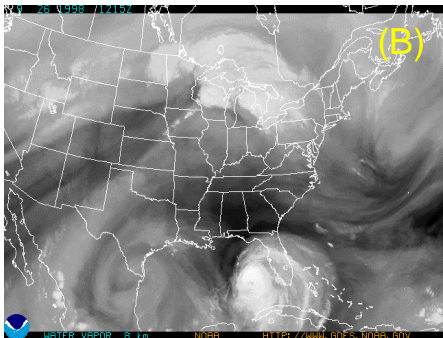
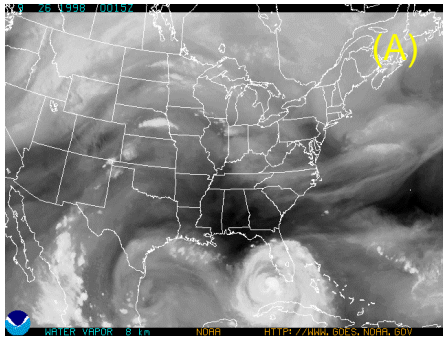
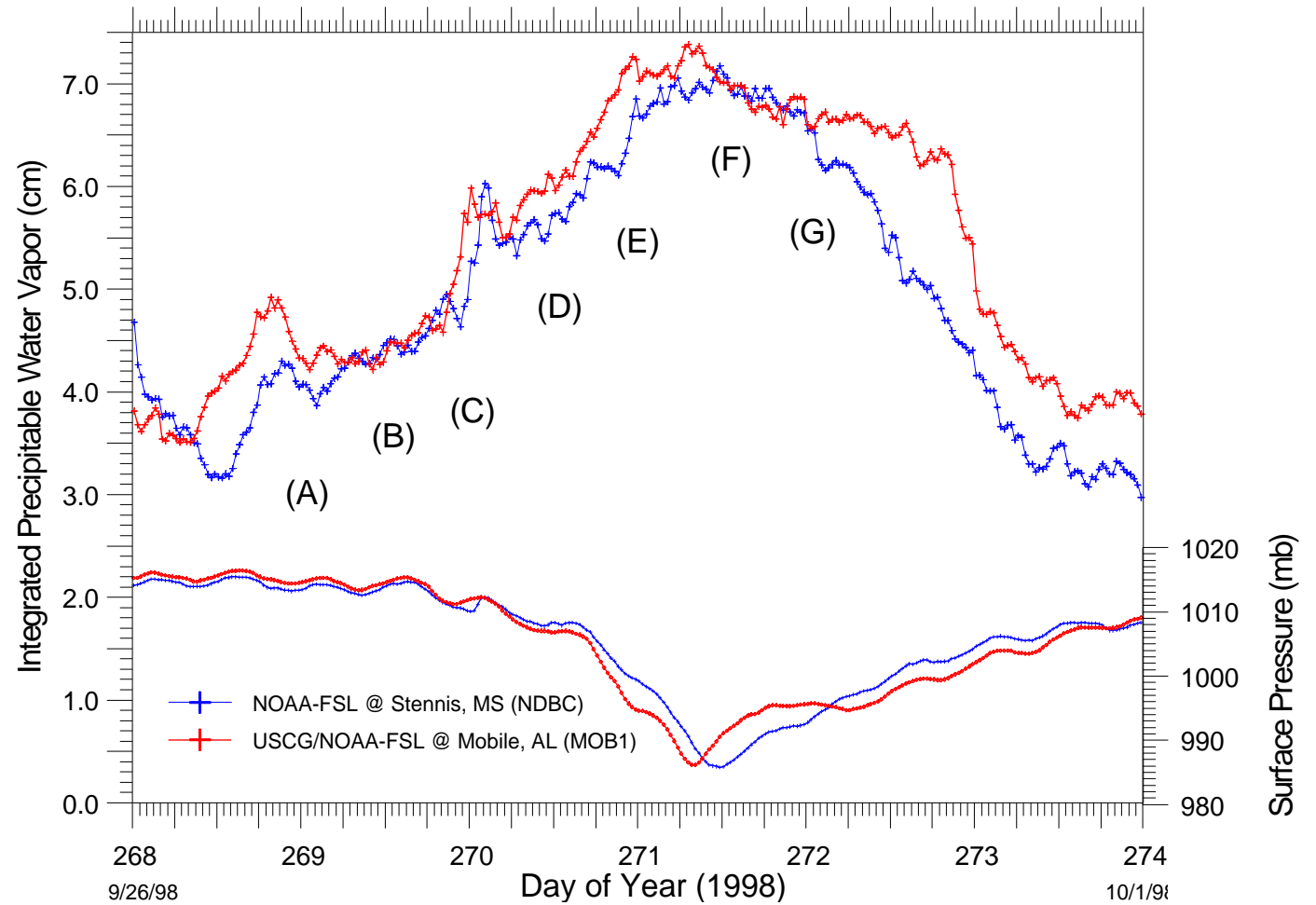


Generalized GPS-IPW Data Processing Scheme





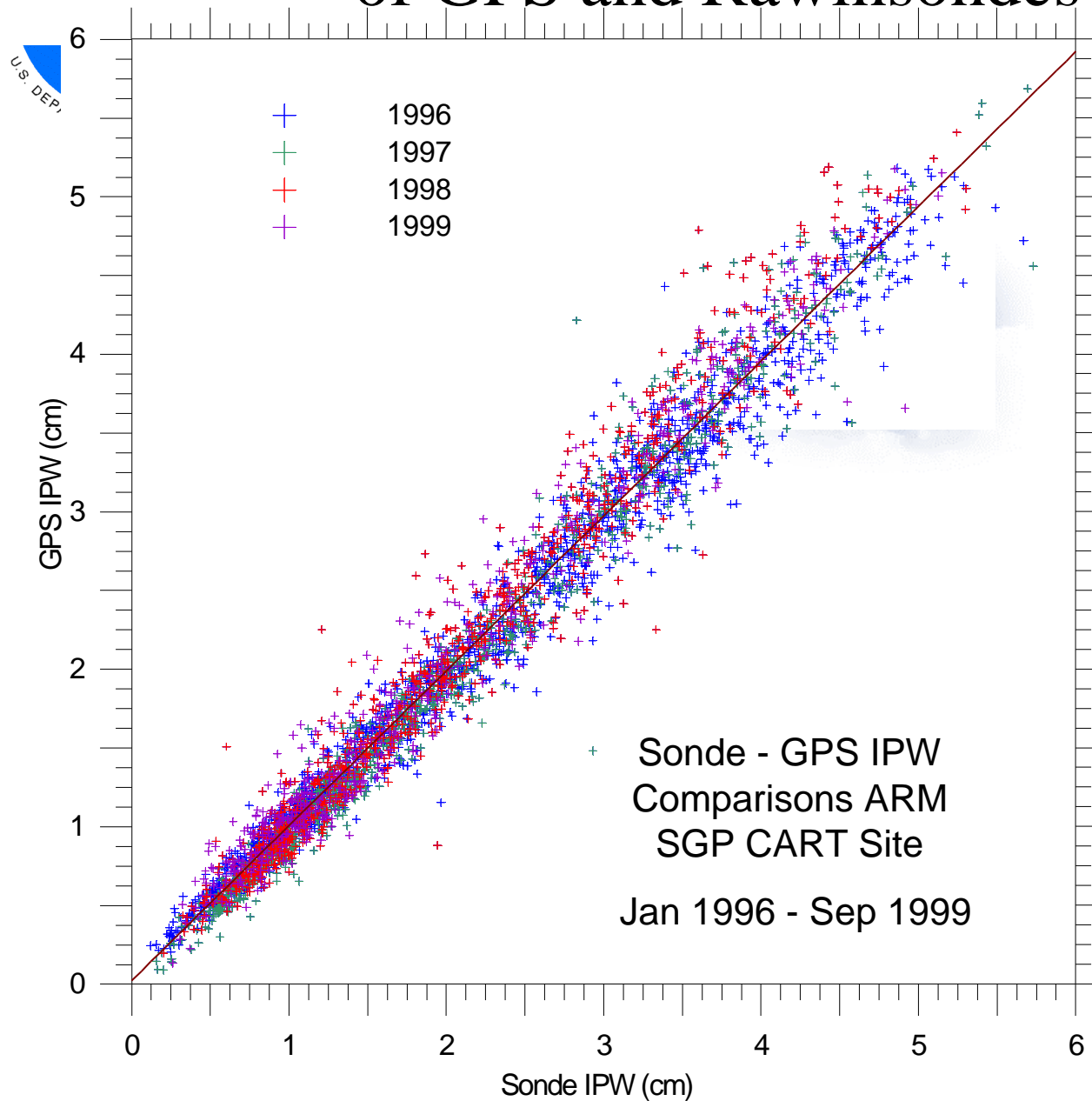
Ground-Based GPS Water Vapor Observations During Hurricane Georges





UPDATED: 10-30-01

Long-Term Comparison of GPS and Rawinsondes



1996

N = 1382
Mean Dif. = 0.0346 cm
Std. Dev. = 0.1977 cm
Corr. = 0.9886

1997

N = 813
Mean Dif. = 0.0501 cm
Std. Dev. = 0.1965 cm
Corr. = 0.9874

1998

N = 771
Mean Dif. = -0.0431 cm
Std. Dev. = 0.2308 cm
Corr. = 0.9817

1999

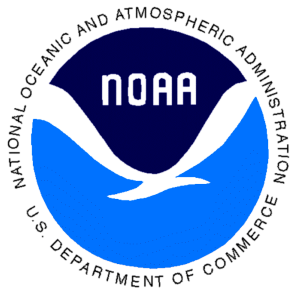
N = 551
Mean Dif. = -0.0460 cm
Std. Dev. = 0.2070 cm
Corr. = 0.9851

1996 - 1999

N = 3600
Mean Dif. = 0.0080 cm
Std. Dev. = 0.2102 cm
Corr. = 0.9854

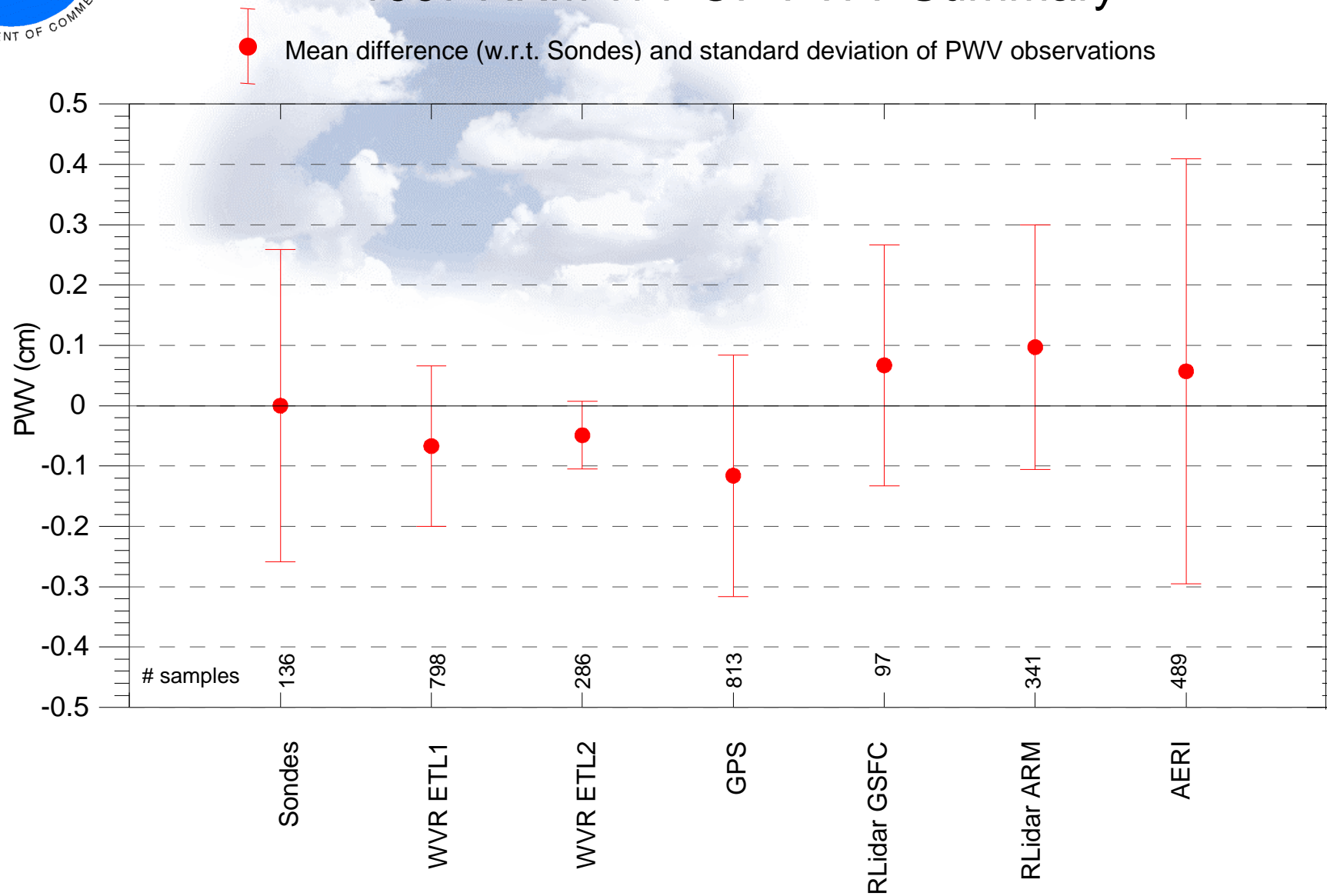
Equation of best fit line

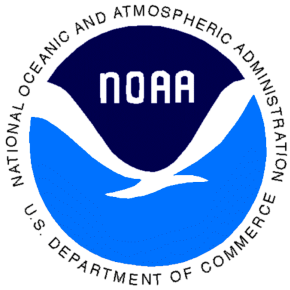
$$Y = 0.9876125443 * X + 0.01837114798$$



PWV Observing System Accuracy

1997 ARM WVIOP PWV Summary





GPS-IPW for AIRS Validation

- Strengths
 - All weather, high accuracy, 30 minute resolution,
 - Operational
- Limitations
 - Currently restricted to CONUS
 - No vertical resolution; for profiles, serves as constraint
- Schedule
 - Ready immediately
 - Need to integrate w/ Wolf *et al* for “All-way” match-ups
- Special needs - None